

WEST Search History

DATE: Monday, November 02, 2009

Hide? Set Name Query

Hit Count

Prior Art

DB=USPT; PLUR=YES; OP=ADJ

<input type="checkbox"/>	L120	1119 and feedback same motion and gravity and table	12
<input type="checkbox"/>	L119	foot and L115	440
<input type="checkbox"/>	L118	foot and L116	1
<input type="checkbox"/>	L117	float\$4 and L115	161
<input type="checkbox"/>	L116	"0" and L114	1
<input type="checkbox"/>	L115	robot\$6 and L113	2038
<input type="checkbox"/>	L114	L112 and zmp	1
<input type="checkbox"/>	L113	(700/245 1700/246 1700/251 1700/253 1700/260 1700/261 318/568.1 1 318/568.12 1318/568.16 1318/568.17 1318/568.2 901/1 1901/9 1901/46 180.1).ccls.	2344
<input type="checkbox"/>	L112	((("6962220")!.PN.) .p67-p150.	1

DB=PGPB,USPT,EPAB,JPAB,DWPI,TDBD; PLUR=YES; OP=ADJ

<input type="checkbox"/>	L111	robot\$6 and (walk\$3 or biped or humanoid or two legged) and (inlina\$6 or betn or tilt or deviat\$5 or obliqu\$5 or indirect\$4 or change direction or slope or slant)	6807
<input type="checkbox"/>	L110	('6711469' '6697709' '6567724' '6505098' '6493606' '6480761' '6330494' '6289265' '6243623')!.ABPN1,NRPN,PN,TBAN,WKU.	16
<input type="checkbox"/>	L109	marc.xa. and legged and inclination	37
<input type="checkbox"/>	L108	marc.xa. and legged and inclinaiton	0
<input type="checkbox"/>	L107	('5404086')!.ABPN1,NRPN,PN,TBAN,WKU.	2
<input type="checkbox"/>	L106	(editing or updating) and (motion or traject\$4 or movement) and zmp and robot\$6	31
<input type="checkbox"/>	L105	(editing or updating) same (motion or traject\$4 or movement) and zmp and robot\$6	14
<input type="checkbox"/>	L104	(editing or updating) same (motion or traject\$4 or movement) and L102	3

<input type="checkbox"/>	L103	robot and zmp and yaw	179
<input type="checkbox"/>	L102	marc.xa. and zmp	49
<input type="checkbox"/>	L101	10/181500	3
<input type="checkbox"/>	L100	('66977709' !'6289265' !'6243623')!.ABPN1,NRPN,PN,TBAN,WKU.	6
<input type="checkbox"/>	L99	marc.xa. and robot and zmp	49
<input type="checkbox"/>	L98	(motions or movement or displacement) and L96	858
<input type="checkbox"/>	L97	computer and L95	4
<input type="checkbox"/>	L96	record\$3 and L94	1015
<input type="checkbox"/>	L95	(request or command) and L93	4
<input type="checkbox"/>	L94	L89 and L92	2318
<input type="checkbox"/>	L93	execut\$5 and L91	6
<input type="checkbox"/>	L92	run or L89	1460106
		(6458772 or 6284156 or 6348461 or 6262044 or 6410586 or 6342245 or 6277877 or 6399557 or 3857856 or 5835892 or 6376445 or 6440911 or 6163111 or 5610305 or 5230889 or 4391489 or 4483594 or 6410749 or 4876009 or 6358945 or 6281227 or 6391397 or 6432994 or 4920120 or 5874378 or 6374641 or 5384779 or 5523998 or 5537098 or 4260406 or 4293439 or 4386503 or 5179438 or 5208607 or 6275216 or 5534261 or 5640119 or 5831440 or 6049212 or 6271251 or 4949326 or 5015815 or 5194938 or 4870247 or 6258470 or 6316465 or 6388989 or 4505827 or 5210848 or 5230070).pn.	100
<input type="checkbox"/>	L91		
<input type="checkbox"/>	L90	(similar or "same") function and L88	1
<input type="checkbox"/>	L89	robot and control software and (chang\$3 or replac\$5)	2318
<input type="checkbox"/>	L88	('20050125099')!.ABPN1,NRPN,PN,TBAN,WKU.	2
<input type="checkbox"/>	L87	(10/126774 10/970977 10/935607 10/919172 10/775845 10/732446 10/726597 10/683496 10/637890)	18
<input type="checkbox"/>	L86	(motion or displacement or trajector\$3) and L84	20
<input type="checkbox"/>	L85	(humanoid or two legged robot and human like robot) and zmp and comput\$5	124
<input type="checkbox"/>	L84	zmp and "approximately 0"	20
		DB=PGPB,USPT; PLUR=YES; OP=ADJ	
<input type="checkbox"/>	L83	((("20060106495")!.PN.).PGPB. ((("7119510")!.PN.).USPT.	2
		DB=PGPB,USPT,EPAB,JPAB,DWPI,TDBD; PLUR=YES; OP=ADJ	
<input type="checkbox"/>	L82	grasping and L80	7

<input type="checkbox"/>	L81	horizontal and vertical and L79	17
<input type="checkbox"/>	L80	signal and detection and L78	38
<input type="checkbox"/>	L79	distance and L77	17
<input type="checkbox"/>	L78	center and L76	46
<input type="checkbox"/>	L77	motion and L75	22
<input type="checkbox"/>	L76	gravity and L74	49
<input type="checkbox"/>	L75	floor reaction and L73	24
<input type="checkbox"/>	L74	foot and robot and ground contact and sensor and sole and joint and reaction and force and walk\$3	60

DB=PGPB; PLUR=YES; OP=ADJ

<input type="checkbox"/>	L73	L71	27
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DB=PGPB,USPT,EPAB,JPAB,DWPI,TDBD; PLUR=YES; OP=ADJ

<input type="checkbox"/>	L72	10/553278	1
<input type="checkbox"/>	L71	L69 and robot	47
<input type="checkbox"/>	L70	metatarsophalangeal	595
<input type="checkbox"/>	L69	ground and contact and L66	52
<input type="checkbox"/>	L68	groung and contact and L66	0
<input type="checkbox"/>	L67	sensor and L65	3
<input type="checkbox"/>	L66	axis and L64	76
<input type="checkbox"/>	L65	soles and L63	3
<input type="checkbox"/>	L64	foot and L62	89
<input type="checkbox"/>	L63	L61 and coordinate	3
<input type="checkbox"/>	L62	position and orientation and L60	89
<input type="checkbox"/>	L61	(L32 or L33) and L59	3
<input type="checkbox"/>	L60	landed and landing and foot and robot\$6	167
<input type="checkbox"/>	L59	landed and landing and foot and footstep and robot\$6	7
<input type="checkbox"/>	L58	landed and landing and foot and footstep and (L32 or L33)	3
<input type="checkbox"/>	L57	landded and landing and foot and footstep and (L32 or L33)	0
<input type="checkbox"/>	L56	landded and landing and foot and footstep and L46	0
<input type="checkbox"/>	L55	landded and landing and foot and L53	0
<input type="checkbox"/>	L54	posture and L52	0

<input type="checkbox"/>	L53	gravity and coordinate and L51	1370
<input type="checkbox"/>	L52	estimat\$3 and position and L50	4
<input type="checkbox"/>	L51	dynamics same model and L47	15766
<input type="checkbox"/>	L50	dyanamics and L47	37
<input type="checkbox"/>	L49	dyanamics same model and L47	3
<input type="checkbox"/>	L48	L45 and L46	0
<input type="checkbox"/>	L47	movement or trajectory and L45	2797189
<input type="checkbox"/>	L46	floor and zmp and L32	1
<input type="checkbox"/>	L45	floor and zmp and L43	0
<input type="checkbox"/>	L44	(5024920 5173382 5490103 5557564 5901829 6201488 6521838 6518503 6695663 6592418 5733819 6027554 6663326 6694847 6685863 4252414 4588518 4561746 4719331 5118090 5434926 5419740 5558196 5527940 5716481).pn.	48
<input type="checkbox"/>	L43	motion pattern and L40	0
<input type="checkbox"/>	L42	motion pattern and stor\$3 and L40	0
<input type="checkbox"/>	L41	freedom and L39	26615
<input type="checkbox"/>	L40	L37 and L38	0
<input type="checkbox"/>	L39	L37 and gait or gate	1334093
<input type="checkbox"/>	L38	('6580969' '6493606' '6463356' '6289265' '6243623' '5872893' '5841258' '5838130' '5594644' 'EP 1136193A' 'EP 1103451A')!.ABPN1, NRPN,PN,TBAN,WKU.	18
<input type="checkbox"/>	L37	('20030019671' '20020138359' '6591923' '6458011')!.ABPN1,NRPN,PN, TBAN,WKU.	7
<input type="checkbox"/>	L36	(legged robot or pet robot or humanoid near10 robot) motion and pattern	15
<input type="checkbox"/>	L35	(legged robot or pet robot or humanoid near10 robot) motion and pattern and L33	8
<input type="checkbox"/>	L34	(6252544 6493606 6243623 6289265 5673367 5355064 5455497 5325031 5357433 5594644 6580969 6718231 5504841 5842533 4621333 4633059 4987527 5937398 6064168 6429812 6584377 5259064 5349646 5946041 4540211 4762261 5273296 5616917 5627440 5794621 6059092 6059092 6068201 6456728 6505098 6711469 5402050 5525883 5841258 6463356 4614504 5040626 5343397 5369346 5378969 5644204 5672924 5838130 5872893 6229552).pn.	97

<input type="checkbox"/>	L33	(700/245 I700/246 I700/251 I700/253 I700/260 I700/261 or 318/568.1 I 318/568.12 I318/568.16 I318/568.17 I318/568.2 or 901/1 I901/9 I901/46 or 180/8.1 I180/8.6 I180/65.1 or 701/23 or 320/116 I320/120 or 446/376 I 446/384).cccls.	11151
<input type="checkbox"/>	L32	6580969.pn.	2
<input type="checkbox"/>	L31	11/456454	2
<input type="checkbox"/>	L30	10/511608	1
	<i>DB=USPT; PLUR=YES; OP=ADJ</i>		
<input type="checkbox"/>	L29	((("6243623" I "5455497")!.PN.).USPT.	2
	<i>DB=PGPB,USPT,EPAB,JPAB,DWPI,TDBD; PLUR=YES; OP=ADJ</i>		
<input type="checkbox"/>	L28	takenaka.in. and legged robot and force reaction and sensor and joints and floor	2
<input type="checkbox"/>	L27	L25 and 2000	11
<input type="checkbox"/>	L26	L25 and -2000	0
<input type="checkbox"/>	L25	(6920374 or 7496428 or 7493192 or 7487011 or 7379789 or 7337040 or 7337039 or 7319919 or 7319918 or 7319917 or 730833).pn.	26
	<i>DB=PGPB; PLUR=YES; OP=ADJ</i>		
<input type="checkbox"/>	L24	10/562168	1
	<i>DB=PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD; PLUR=YES; OP=ADJ</i>		
<input type="checkbox"/>	L23	L20 and feedback	206
<input type="checkbox"/>	L22	L21 and feedback	10
<input type="checkbox"/>	L21	L20 and cart	14
<input type="checkbox"/>	L20	L16 and gravity	425
<input type="checkbox"/>	L19	"center of gravity"	1
	<i>DB=USPT; PLUR=YES; OP=ADJ</i>		
<input type="checkbox"/>	L18	"center of gravity"	0
<input type="checkbox"/>	L17	L16 and "center of gravity"	0
<input type="checkbox"/>	L16	time derivative and acceleration	1421
<input type="checkbox"/>	L15	L14 and "table-cart"	0
<input type="checkbox"/>	L14	L13 or android	1283
<input type="checkbox"/>	L13	humanoid or walking robot or legged robot	1173
<input type="checkbox"/>	L12	L11 and model	1

<input type="checkbox"/>	L11	L10 and motion	1
<input type="checkbox"/>	L10	L5 and sensor	1
<input type="checkbox"/>	L9	L5 and feedback	0
<input type="checkbox"/>	L8	L5 and feedback and motion	0
<input type="checkbox"/>	L7	L6	0
<input type="checkbox"/>	L6	L5 and feedback and motion	0
<input type="checkbox"/>	L5	L4 and gravity	1
<input type="checkbox"/>	L4	L2 and acceleration	1
<input type="checkbox"/>	L3	L2 and derivative	0
<input type="checkbox"/>	L2	L1 and table	1
<input type="checkbox"/>	L1	6301524.pn.	1

END OF SEARCH HISTORY